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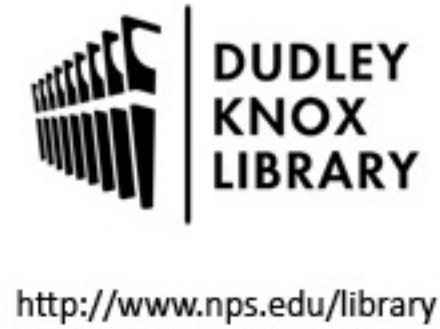

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THESIS

MULTIPLE SENSOR TRACKING IN THE
INTERIM BATTLE GROUP TACTICAL TRAINER

by

Keith N. Spangenberg

March 1985

Thesis Advisor: Rex H. Shudde

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The thesis provides two subroutines for the Interim Battle Group Tactical Trainer (IBGTT). The first subroutine is a single sensor tracking model using the Kalman filter. This subroutine is part of the Passive Sonar Model. The second subroutine is a multiple sensor tracking model using the Kalman filter to correlate all sensor contacts on a specific target. This subroutine is a separate entity and can be turned

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Multiple Sensor Tracking in the Interim Battle Group Tactical Trainer

by

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Lieutenant, United States Navy
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Submitted in partial fulfillment of the
requirements for the degree of

MASTER OF SCIENCE IN SYSTEM TECHNOLOGY
(ANTISUBMARINE WARFARE)

from the

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March 1985

ABSTRACT

The thesis provides two subroutines for the Interim Battle Group Tactical Trainer (IBGTT). The first subroutine is a single sensor tracking model using the Kalman filter. This subroutine is part of the Passive Sonar Model. The second subroutine is a multiple sensor tracking model using the Kalman filter to correlate all sonar contacts on a specific target. This subroutine is a separate entity and can be turned on or off at simulation initiation as required by training objectives.

THESIS DISCLAIMER

The reader is cautioned that computer programs developed in this research may not have been exercised for all cases of interest. While every effort has been made, within the time available, to ensure that the programs are free of computational and logic errors, they cannot be considered validated. Any application of these programs without additional verification is at the risk of the user.

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I. INTRODUCTION

The Naval Ocean Systems Center has developed the Interim Battle Group Tactical Trainer/Computer Support Facility (IBGTT/CSF) as a computer-based tactical simulation system to provide a training device for senior naval officers to practice tactical decision making until such time as the Enhanced Naval Warfare Gaming System becomes available. The trainer is intended to provide interactive, multithreat, multiplatform operational situations in a simulated yet realistic operational environment so that selected officers can study, practice, and be evaluated in force-level tactical decision making.

The IBGTT training capability is implemented as a real-time, man-interactive, computer-aided (discrete event, time step) simulation of the naval warfare environment. In operation, the IBGTT supports a two-sided (BLUE vs. ORANGE) interactive scenario in which opposing sides can define, structure, and dynamically control forces ranging in size from one or more battle groups and associated aircraft, down to a single air or surface unit. Force elements and their associated characteristics, sensors, weapons, and communication systems may be derived from real, proposed, or conceptualized units or systems.

The utilization of IBGTT involves the use of the four major Naval Warfare Interactive Simulation System (NWISS) processes; BUILD, FORCE, WARGAME, and POST-GAME ANALYSIS. The BUILD process is a stand alone interactive program used to create and maintain platform, sensor, communication, and weapon characteristics in the IBGTT Characteristic Data Base. The FORCE process is a stand alone interactive program used to create and maintain an exercise scenario using the

data base created by the BUILD process. The WARGAME process is an interactive program used to accept and execute user orders; control platform motion, detections, and communications; determine engagement and other event outcomes; and display status information and tactical situations. The POST-GAME ANALYSIS process analyzes and lists critical data recorded during the exercise; supports exercise reconstruction; and tentatively evaluates some Measures of Effectiveness.

A global data area in NWISS, called the blackboard, is shared by all the major modules functioning during the exercise. It is the area where these modules interface with each other through the application of uniform naming conventions and the efficient use of memory. The blackboard is essentially comprised of numerous tables and subtables. Each table is assigned specific pointers while each subtable is assigned specific indices. The tables and subtables contain the fields (data) that are unique to that particular table or subtable. Each data item in the blackboard is referred to as a field and includes both whole words and specific bits. The field names are structured to provide the identity of the associated pointers and indices as well as the data type in the field.

Effective training at this level requires models of naval warfare interactions which provide realistic results based on an emulation of the actual warfare system. NWISS uses a wide variety of models to simulate the behavior of platforms, weapons, sensors, and communication systems. However, many of these models do not emulate the actual warfare system nor do they provide realistic results. Therefore, it is necessary to improve or replace these deficient models in order to obtain effective training and meet the objectives for which IBGTT was designed.

This thesis will address two models in particular. The first model is the Target Motion Analysis (TMA) Model which processes passive sonar contacts. The current model will be examined, followed by a presentation of a Kalman filter improvement to the model. Secondly, the Sonar Correlation Model will be examined, followed by a presentation of a Kalman filter to replace the current model.

The reader should be advised that the TMA Kalman Filter Model is in actuality equivalent to the Sonar Correlation Kalman Filter Model, as will become evident in the presentation of the two Kalman Filter Models. This thesis further presupposes that the reader is familiar with the Kalman filter.

II. SINGLE SENSOR TRACKING

A. TARGET MOTION ANALYSIS (TMA) MODEL

The current model will monitor the number of game minutes for which passive contact has been held on each target by each detecting passive sonar (i.e., submarine, surface sonar, towed array, or sonobuoy). When this time exceeds the TMA time defined by the user at simulation initiation a target motion analysis report will be displayed on the Passive Sonar Status Board. The TMA range, course, and speed displayed are derived as follows:

$$\text{TMA}\begin{bmatrix}\text{range}\\ \text{course}\\ \text{speed}\end{bmatrix} = \text{Actual target}\begin{bmatrix}\text{range}\\ \text{course}\\ \text{speed}\end{bmatrix} \pm \text{FACTOR}$$

The FACTOR is the product of a random number drawn from a uniform distribution and a derived parameter.

These parameters, which are indicated in Table I, cause increasingly accurate solutions to be developed as Signal Excess (SE) increases and as the target's true bearin, changes (•B=delta B) from the true bearing of its initial detection. This latter factor simulates improved solutions derived from higher bearing rate targets and longer tracking times. The solution quality displayed will be selected from Table II as a function of SE and •B.

Once a TMA solution has been displayed, only the range is updated on the display. The range only update continues until the signal excess and/or change in true bearing cause a new parameter to be developed from the table (e.g., SE changes from -6 to -5 or •B changes from 5 to 6). When a new parameter is selected, a new TMA range, course, and quality

TABLE I

TMA Error Parameters

RELATIVE RANGE ERROR

SIGNAL EXCESS (SE) IN dB \ BEARING CHANGE IN DEGREES (•B)	•B≤5	5<•B≤15	15<•B≤45	45<•B
SE ≤ -12	R	.8R	.7R	.4R
-12 < SE ≤ -6	.8R	.7R	.4R	.25R
-6 < SE ≤ 0	.7R	.4R	.25R	.1R
0 < SE	.4R	.2R	.1R	.05R

COURSE ERROR IN DEGREES

SIGNAL EXCESS (SE) IN dB \ BEARING CHANGE IN DEGREES (•B)	•B≤5	5<•B≤15	15<•B≤45	45<•B
SE ≤ -12	120	90	45	30
-12 < SE ≤ -6	90	45	30	15
-6 < SE ≤ 0	45	30	15	7
0 < SE	30	15	7	5

RELATIVE SPEED ERROR

SIGNAL EXCESS (SE) IN dB \ BEARING CHANGE IN DEGREES (•B)	•B≤5	5<•B≤15	15<•B≤45	45<•B
SE ≤ -12	.5S	.4S	.3S	.2S
-12 < SE ≤ -6	.4S	.3S	.2S	.1S
-6 ≤ SE ≤ 0	.3S	.2S	.1S	.05S

0 < SE	.2S	.1S	.05S	0

R = Actual Range
S = Actual Speed

TABLE II

TMA Quality

SIGNAL EXCESS (SE) IN dB	BEARING CHANGE IN DEGREES (•B)	•B<5	5<•B≤15	15<•B≤45	45<•B
SE ≤ -12		POOR	POOR	FAIR	FAIR
-12 ≤ SE ≤ -6		POOR	FAIR	FAIR	FAIR
-6 ≤ SE ≤ 0		FAIR	FAIR	FAIR	GOOD
0 < SE		FAIR	FAIR	GOOD	GOOD

will be calculated and displayed. Between TMA changes, the displayed range is updated each simulation cycle to show the range of the target estimated from the TMA course and speed.

If contact is lost for a time greater than the user-defined track loss time, the TMA solution will no longer be displayed. At any subsequent redetection of the same target, a new solution will be generated after the appropriate time interval has passed.

B. KALMAN FILTER IMPROVEMENTS

The model does not begin tc compute a track until the TMA time defined by the user at simulation initiation is exceeded. This implies that all sensors and operators are equal, which is not realistic. Furthermore, this does not allow for accurate information to be used at time of detection unless the TMA time has already been exceeded. For instance, a passive sonobuoy dropped in front of a contact, producing a CPA (closest point cf approach) for its initial detection, would have good track information that would not be utilized by the mcdel; for only information after the TMA time is used in determining the FACTOR.

This TMA initiation time was included in the model because use of actual target information provided too accurate of a fix, even with bad sensor information, for a player to experience a realistic prosecution. The Kalman Filter Mcdel eliminates the need for this waiting time since the model receives information as an operator would see it (that is, appparent bearing resulting from apparent position, including navigation error, and sensor bearing error). Thus, the Kalman Filter Model allows use of all sensor information with appropriate errors to provide realistic prosecution.

The TMA model attempts to simulate a changing area of probability (AOP) with improved solutions taken from the table as SE increases and true bearing changes. The problem of using true information instead of apparent has already been discussed. In addition, the improved AOP is heavily dependent upon the drawing of a random number. It has been observed in actual trainers that the AOP fluctuates as randomly as the random number generator, regardless of sensor information; providing confusing information to the player. Again, the Kalman Filter Model eliminates this

problem since the computed AOP updates smoothly with the sensor information.

C. KALMAN FILTER MODEL

First of all, it is assumed that during an encounter, the target's course and speed remain constant. The model updates the position of the fix since the last observation based on the previous estimate. This is based on the system model:

$$X(t) = PHI(t-1)*X(t-1)+W(t-1)$$

Thus, movement is:

State Extrapolation: X$hat(t) = PHI(t-1)*X$hat(t-1)

and

Error Covariance Extrapolation:

$$P(t) = PHI(t-1)*P(t-1)*PHI\$transpose(t-1) + Q(t-1)$$

where

X$hat is the estimated state vector. It is assumed to be multivariate normal with mean zero.

$$X(t) = [\ x(t)\quad y(t)\quad x'\quad y'\ ]\$transpose$$

x'= x velocity

y'= y velocity

PHI is the transition matrix. It describes how the state vector changes from X(t) to X(t+1).

$$PHI = \begin{bmatrix} 1 & 0 & \bullet t & 0 \\ 0 & 1 & 0 & \bullet t \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

•t=delta t

P is the error covariance matrix.

$$P(t) = E[\{X(t)-X\$hat(t)\}*\{X(t)-X\$hat(t)\}\$transpose]$$

W(t) is the plant noise. It describes the randomness of the system as it moves from state X(t) to X(t+1). W(t) is approximately N(0,Q(t)). For this model, Q is taken to be zero.

Next, a new fix is computed based on an observation. This is determined from the measurement model:

$$Z(t) = H(t)*X(t) + V(t)$$

Thus, measurement is:

Kalman Gain: K(t)=

$$P(t)*H\$transpose(t)*[H(t)*P(t)*H\$transpose(t) + R(t)]^{-1},$$

State Update:

$$X\$hat(t) := X\$hat(t) + K(t)*[Z(t)-H(t)*X\$hat(t)],$$

and

Error Covariance Update:

$$P(t) := P(t)-K(t)*[P(t)*H\$transpose(t)]\$transpose$$

where

:= indicates that the right hand side is computed and replaces the value on the left hand side of the symbol.

Z(t) is the actual measurement. The measurements are assumed to be linearly related to the system state X(t) by the observation matrix H(t). Note: H(t)*X\$hat(t) is the predicted outcome of the measurement. The difference, Z(t)-H(t)*X\$hat(t), is the measurement residual or shock.

V(t) is the measurement noise. It is approximately N(0,R(t)). For this model, all bearings are ± .5 degrees.

K(t) is the Kalman gain. The update from X$hat(t) just before the measurement to X$hat(t) just after the measurement is proportional to the shock; the Kalman gain is the proportionality constant.

It was stated earlier that the measurements are assumed to be linearly related to the system state. Since the measurement is in polar coordinates, h(x) is in fact nonlinear. Therefore, a transformation must be made on h(x) to give a linearly related H.

In this model, the observation will be made from a platform at (u,w) to a target at (x,y), where x is north and y is east. So,

$$h(X) = \text{theta} = \tan^{-1}[(y-w)/(x-u)]$$

or,

$$H = [\ \partial h(X)/\partial x \quad \partial h(X)/\partial y \quad \partial h(X)/\partial x' \quad \partial h(X)/\partial y'\ ]$$

∂ represents the partial derivative

evaluated at X = X$hat. Hence,

$$H = [\ -\sin(\text{theta})/\text{range} \quad \cos(\text{theta})/\text{range} \quad 0 \quad 0\ ]$$

This model was built upon two initial conditions and two important assumptions. The initial conditions are:

$$E[X(0)] = X\$hat(0)$$

and

$$E[\{X(0)-X\$hat(0)\}*\{X(0)-X\$hat(0)\}\$transpose] = P(0)$$

where

$$X\$hat(0) = [\ 32\cos\theta_0 \quad 32\sin\theta_0 \quad 0 \quad 0\ ]\$transpose$$

θ_0 is the initial observation

and

$$P(0) = \begin{bmatrix} 1000 & 0 & 0 & 0 \\ 0 & 1000 & 0 & 0 \\ 0 & 0 & 1000 & 0 \\ 0 & 0 & 0 & 1000 \end{bmatrix}$$

Note: 1000 was chosen since it is approximately equal to ± one convergence zone (32 nm) and ± 32 knots.

The first assumption is that

$$E[W(k)*V(j)\$transpose] = 0 \quad \text{for all } j \text{ and } k.$$

This means that the plant noise and the measurement noise are uncorrelated. Secondly, recall that the assumption is that during an encounter, the target's course and speed remain constant.

D. TRACK QUALITY

In order to reduce the number of changes required to the overall program, the TMA quality currently used from Table II will be utilized but based on different criteria. This will eliminate the need to change the blackboard; and more importantly, will not change the Status Tableau seen by the player, which is already full.

The track quality is based on the semi-major axis of the AOP. This is determined from the error covariance matrix as follows:

$$(\text{semi-major axis})^2 = (p11+p22)/2+\text{SQRT}[(p11-p22)^2/4+p12^2]$$

where pij are the elements of the P(t) matrix. A 2-sigma semi-major axis is used to insure a probability of 0.8647. The track quality is then determined as follows:

- If the 2-sigma axis is less than or equal to 500 yards, then the track receives a quality of GOOD. The criteria of 500 yards is used because the Engagement Model employs a 500 yard kill radius for a torpedo.
- If the 2-sigma axis is greater than 500 yards but less than or equal to 1000 yards, then the track receives a quality of FAIR. The criteria of 1000 yards was chosen simply because it is twice the GOOD criteria.
- If the 2-sigma axis is greater than 1000 yards, then the track receives a quality of POOR.

E. CHANGES TO OTHER SUBROUTINES

Implementation of this subroutine (LCLTMA, rational FORTRAN and source code listing are contained in Appendix A and B, respectively) will require some changes to other subroutines and additions to the blackboard. These changes and/or additions include:

1. Subroutine WARCYC

Each target needs a P(0) matrix in the blackboard; therefore, add:

```
      REAL PBB(4,4)
      REAL I_LCL$PMATRIX(4,4),I_RMT$PMATRIX(4,4)
      DO 50000 J=1,4
      DO 50001 K=1,4
      IF(.NOT.(J.EQ.K))GOTO 50001
      PBB(J,K) = 1000.
      GOTO 50000
50001 PBB(J,K) = 0.
50000 CONTINUE
      I_LCL$PMATRIX = PBB
      I_RMT$PMATRIX = PBB
```

2. Subroutine LCLPSN

- Change line 9 to read:

```
EQUIVALENCE (IBB,FBB,CBB,IBBW,IBBB,PBB)
```

This includes the blackboard of the P matrix.

- After line 113 add:

```
I_LCL$LASTTMATIME=(IAND(ISHFT(IBB(KPOINT_LCL
*+1),-0),65535)
```

This time is used in Subroutine LCLTMA.

- Change line 262 to read:

```
IF(.NOT.(I_ICL$OMNIFLAG.NE.1))GOTO 23269
```

This removes the TMA exceed time criteria.

- Change line 264 to read:

```
 LCLTMA(KPOINT_LCL,RORLAT,RORLON,LBEAR,
*I_LCL$PMATRIX,I_LCL$IASTTMATIME)
```

III. MULTIPLE SENSOR TRACKING

A. SONAR CORRELATION MODEL

The Sonar Correlation Model would be more appropriately described as a procedure instead of a model. This routine determines the correlation of bearings between two detecting units at a specific target and performs two functions. First, the two detecting units (with an intersection angle of at least 60 degrees, or else the largest available angle) to a common target will display bearing lines. Second, multiple targets detected within a certain maximum arc will display only one line; and will set the composition field set (i.e., one, few, or many). All other passive sonar lines will not be displayed.

The Sonar Correlation Model can be turned on or off. This allows for the flexibility of being utilized for Battle Group Commanders and their staff when the "big picture" is the main concern and not the individual unit prosecution; and yet, be turned off when the trainer is being utilized for a single unit or group of units practicing coordinated operations.

B. KALMAN FILTER REPLACEMENT

The current procedure has many drawbacks. Only passive sonar lines are considered; active information is displayed separately and is not correlated with the passive information.

The routine searches through the Remote Table until it finds two bearing lines that meet the 60 degree criteria. These are displayed and the routine ceases to search; thus, not necessarily choosing the optimum solution. In addition,

no fix or track is associated with the correlation. As a result, each game minute two bearing lines are displayed (they may not be the same two from the previous minute nor necessarily an improvement) that jump around the screen, providing no useful information to the user.

The Kalman Filter Model permits all the information available, both active and passive, to be correlated on a specific target and be displayed as a fix with an updated track. In addition, the track quality associated with the fix provides the user with the added information about the relative size of the AOP. The on and off ability of the Sonar Correlation Model will be incorporated into the Kalman Filter Model for the previously stated reasons concerning its flexibility.

C. KALMAN FILTER MODEL

As mentioned in the introduction, the single sensor tracking model is in actuality equivalent to the multiple sensor tracking model. The difference being the scope of the information being processed. The single sensor model is a subset of the Passive Sonar Model; whereas, the Multiple sensor model is a separate entity correlating all available information. The basics of the models, including assumptions and initial conditions, are the same. Therefore, only the differences from the single sensor tracking model, presented in Chapter Two, will be discussed here.

The model will handle bearing and range measurements as well as bearing only measurements. The bearings are ±.5 degrees and the ranges are ±.5 nautical miles. For the bearing only measurement, the H matrix will be the same as for the single sensor tracking model. For the bearing and range measurement, the following H matrix will be utilized:

$$H = \begin{bmatrix} -\sin(\text{theta})/\text{range} & \cos(\text{theta})/\text{range} & 0 & 0 \\ \cos(\text{theta}) & \sin(\text{theta}) & 0 & 0 \end{bmatrix}$$

The track quality will be the same as that presented in Chapter Two.

D. CHANGES TO OTHER SUBROUTINES

The rational FORTRAN and source code listing for this model are contained in Appendix C and D, respectively. The changes presented in Chapter Two for Subroutine WARCYC are also applicable to this model. The only other change that will be necessary is that all active information needs to be added to the Remote Table.

IV. TEST RESULTS

The single sensor and multiple sensor models have been tested on a limited basis. Each subroutine has been tested independently to insure that the models perform as designed. However, the subroutines have not been tested for integration into the overall NWISS program or other subroutines.

Due to time constraints and computer availability, integration tests were not possible. The added blackboard space required has not been made but should not pose any problems. Inherent with any new subroutine is the unforeseeable affect it may have on unrelated subroutines. This aspect of testing has not been performed.

APPENDIX A

SINGLE SENSOR MODEL (RATIONAL FORTRAN)

```
Subroutine LCLTMA(LCL$Pointer,          #LCL Table Pointer              LCL00010
                  RORLAT,               #LAT of BRG-line ORIGIN         LCL00020
                  RORLON,               #LON of BRG-line ORIGIN         LCL00030
                  LBEAR,                #integer SONAR TGT BRG          LCL00040
                                        #      with Heading error       LCL00050
                  I_LCL$PMATRIX,        #Kalman P matrix                LCL00060
                  I_LCL$LASTTMATIME)    #Game minute of last fix update LCL00070
##############################################################################LCL00080
#                                                                             LCL00090
# Purpose:LCLTMA determines TMA solutions for a detector,using a Kalman      LCL00100
#         filter, and stores data (for the Passive Sonar ASTAB) in the        LCL00110
#         LCL Table.                                                          LCL00120
#                                                                             LCL00130
# Called by: LCLPSN                                                         LCL00140
#                                                                             LCL00150
# Calls: MUL4X4  RRB2IL                                                     LCL00160
#                                                                             LCL00170
##############################################################################LCL00180
                                                                            LCL00190
BBcommon                                                                    TLCL00200
```

```
                                                                    LCL00210
real   XEST(4),X(4)                  #System Model State Vector    LCL00220
       PHI(4,4)                      #System Model Transition Matrix LCL00230
       PHIT(4,4)                     #Transpose of Transition Matrix LCL00240
       P(4,4),I_LCL$PMATRIX(4,4)     #Error Covariance Matrix      LCL00250
       H(4)                          #Measurement Model Observation Matrix LCL00260
       K(4)                          #Kalman Gain                  LCL00270
       Z                             #Measurement Vector           LCL00280
                                                                    LCL00290
lcl$TMALAT$F=xlcl$TMALAT$F           #Estimated LAT/LON            LCL00300
lcl$TMALON$F=xlcl$TMALON$F           #                  of TGT     LCL00310
lcl$TMACSE$F=xlcl$TMACSE$F           #Estimated COURSE and         LCL00320
lcl$TMASPD$F=xlcl$TMASPD$F           #          SPEED of TGT       LCL00330
                                                                    LCL00340
#MOVEMENT:                                                         LCL00350
                                     #State Extrapolation:         LCL00360
       XEST(1)=X                     #Distance in north-south direction LCL00370
       ANGPI(DELLON)                 #Insure shortway around earth LCL00380
       XEST(2)=Y                     #Distance in east-west direction LCL00390
       XEST(3)=X$dot                 #Speed vector in north-south directionLCL00400
       XEST(4)=Y$dot                 #Speed vector in east-west direction LCL00410
                                                                    LCL00420
    #Initialize PHI Matrix                                         LCL00430
      PHI(1,3)=PHI(2,4)=$delta$time    #Movement time in hrs since last LCL00440
```

```
                                        #update                          LCL00450
                                                                         LCL00460
    #X$hat=PHI*X$hat                #State Extrapolation Vector          LCL00470
                                                                         LCL00480
    #PHI$transpose                                                       LCL00490
    #P=PHI*P*PHI$transpose          #Error Covariance Extrapolation      LCL00500
                                                                         LCL00510
#MEASUREMENT:                                                            LCL00520
                                                                         LCL00530
    #Estimated bearing                                                   LCL00540
    #Estimated range                                                     LCL00550
                                                                         LCL00560
                                    #Measurement Observation Matrix      LCL00570
      H(1)=-SIN(THETA$hat)/RNG$hat      #H$transpose=H                 LCL00580
      H(2)=COS(THETA$hat)/RNG$hat                                        LCL00590
      H(3)=H(4)=0.                                                       LCL00600
                                                                         LCL00610
    #P*H$transpose                  =(P*H$transpose)$transpose           LCL00620
    #H*P*H$transpose                                                     LCL00630
    #H*P*H$transpose+R              R=BRG measurement error=±.5 degrees  LCL00640
    #Kalman Gain                                                        LCL00650
    #H*X$hat                                                            LCL00660
      ZHX=Z-HX                      #Measurement Residual                LCL00670
    #K*(Z-H*X$hat)                                                      LCL00680
```

```
    #X$hat=X$hat+K*(Z-H*X$hat)     State Update                          LCL00690
                                                                         LCL00700
    #K*(P*H$transpose)$transpose                                         LCL00710
    #P=P-K*(P*H$transpose)$transpose   #Error Covariance Update          LCL00720
                                                                         LCL00730
#New estimated bearing                                                   LCL00740
#New estimated range                                                     LCL00750
                                                                         LCL00760
#Compute LAT/LON of BRG/RNG from ORIGIN                                  LCL00770
      CALL RRB2LL(_                 #Get LAT/LON                       LCL00780
                  F_LCL$TMALAT,     #ORIGIN LAT -> FIX LAT (input/output) LCL00790
                  F_LCL$TMALON,     #ORIGIN LON -> FIX LON (input/output) LCL00800
                  RNG,              #Range from ORIGIN to TGT          LCL00810
                  THETA,            #Bearing from ORIGIN to TGT        LCL00820
                  0.0,              #Pass zero                         LCL00830
                  COSL)             #Cosine of LAT (input/output)      LCL00840
                                                                         LCL00850
putLCL$TMALAT$f               #New FIX position                          LCL00860
putLCL$TMALON$f                                                          LCL00870
                                                                         LCL00880
#New estimated course                                                    LCL00890
#New estimated speed                                                     LCL00900
```

```
                                                                    LCL00910
putLCL$TMACSE$f              #New FIX course                        LCL00920
putLCL$TMASPD$f              #    and speed                         LCL00930
                                                                    LCL00940
#Determine semi-major axis of area of probability                   LCL00950
    #SIGMA$squared=(P11+P22)/2+SQRT{((P11-P22)+(P11-P22))/4+P12*P12} LCL00960
    #2SIGMA=2*SIGMA/2025 yds                                        LCL00970
                                                                    LCL00980
if(2SIGMA <= 500 yds)then                                           LCL00990
   TMA$Quality=2             #GCOD                                  LCL01000
else if(2SIGMA > 500 yds & <= 1000 yds)then                         LCL01010
   TMA$Quality=1             #FAIR                                  LCL01020
else(2SIGMA > 1000 yds)                                             LCL01030
   TMA$Quality=0             #POOR                                  LCL01040
                                                                    LCL01050
return                                                              LCL01060
end           #End lclTMA                                           LCL01070
#####################################################################LCL01080
Subroutine MUL4X4(A,         #4X4 matrix (input)                    LCL01090
                  B,         #4X4 matrix (input)                    LCL01100
                  C)         #4X4 matrix (output)                   LCL01110
#####################################################################LCL01120
#                                                                   LCL01130
```

```
# Purpose: Multiplies two 4X4 matrices together.                    LCL01140
#                                                                   LCL01150
# Called by: LCLTMA  CORSNR                                         LCL01160
#                                                                   LCL01170
#####################################################################LCL01180
                                                                    LCL01190
C=A*B                                                               LCL01200
                                                                    LCL01210
return                                                              LCL01220
end            #End MUL4X4                                          LCL01230
```

APPENDIX B

SINGLE SENSOR MODEL (SOURCE CODE)

```
 SUBROUTINE LCLTMA(KPOINT_LCL,RORLAT,RORLON,LBEAR,I_LCL$PMATRIX,I_LLCL00010
*CL$LASTTMATIME)                                                  LCL00020
 IMPLICIT REAL*8 (A,C)                                            LCL00030
 INTEGER IBB(1025),IBBP(6,85)                                     LCL00040
 INTEGER*2 IBBW(2,1025)                                           LCL00050
 BYTE IBBB(4,1025)                                                LCL00060
 REAL*8 CBB(512)                                                  LCL00070
 REAL FBB(1025),I_LCL$PMATRIX(4,4),P(4,4),KPHTT(4,4),H(4),PHT(4)  LCL00080
 REAL K(4),HPHT,HPHTR,HX,PROD(4),XEST(4),X(4),PHI(4,4),PHIT(4,4)  LCL00090
 REAL PBB(4,1025)                                                 LCL00100
 EQUIVALENCE (IBB,FBB,CBB,IBBW,IBBB,PBB)                          LCL00110
 EQUIVALENCE (IBB(513),IBBP)                                      LCL00120
 COMMON/BBOARD/IBB                                                LCL00130
 F_LCL$TMALAT=(IAND(ISHFT(IBB(KPOINT_LCL+8),-0),65535)*1.*.0001-3.2LCL00140
*)                                                                LCL00150
 F_LCL$TMALON=(IAND(ISHFT(IBB(KPOINT_LCL+8),-16),65535)*1.*.0001-3.LCL00160
*2)                                                               LCL00170
 F_LCL$TMACSE=(IAND(ISHFT(IBB(KPOINT_LCL+5),-0),511))             LCL00180
 F_LCL$TMASPD=(IAND(ISHFT(IBB(KPOINT_LCL+4),-16),4095))           LCL00190
 XEST(1)=F_LCL$TMALAT-RORLAT                                      LCL00200
 DELLON=F_LCL$TMALON-RORLON                                       LCL00210
```

```
      ANGPI(DELLON)                                                    LCL00220
      COST=COS(F_LCL$TMALAT)                                           LCL00230
      COSL=COS(RORLAT)                                                 LCL00240
      XEST(2)=.5*(COSI+COST)*DELLON                                    LCL00250
      XEST(3)=F_LCL$TMASPD*COS(F_LCL$TMACSE)                           LCL00260
      XEST(4)=F_LCL$TMASPD*SIN(F_LCL$TMACSE)                           LCL00270
      DO 50002 J=1,4                                                   LCL00280
      DO 50002 K=1,4                                                   LCL00290
      IF(.NOT.(J.EQ.K))GOTO 50003                                      LCL00300
      PHI(J,K)=1.                                                      LCL00310
      GOTO 50002                                                       LCL00320
50003 PHI(J,K)=0.                                                      LCL00330
50002 CONTINUE                                                         LCL00340
      PHI(1,3)=(IBB(103)-I_LCL$IASTTMATIME)/60.                        LCL00350
      PHI(2,4)=PHI(1,3)                                                LCL00360
      DO 50004 J=1,4                                                   LCL00370
      X(J)=0.                                                          LCL00380
      DO 50004 K=1,4                                                   LCL00390
50004 X(J)=X(J)+PHI(J,K)*XEST(K)                                       LCL00400
      DO 50005 J=1,4                                                   LCL00410
      DO 50005 K=1,4                                                   LCL00420
50005 PHIT(J,K)=PHI(K,J)                                               LCL00430
      CALL MUL4X4(PHI,I_LCL$PMATRIX,P)                                 LCL00440
      CALL MUL4X4(P,PHIT,I_LCL$PMATRIX)                                LCL00450
```

```
      THETA=FATAN2(X(2),X(1))                                          LCL00460
      THETA=INT(THETA*(180./3.141592654)+.5)                           LCL00470
      RNG=SQRT(X(1)*X(1)+X(2)*X(2))                                    LCL00480
      H(1)=-SIN(THETA)/RNG                                             LCL00490
      H(2)=COS(THETA)/RNG                                              LCL00500
      H(3)=0.                                                          LCL00510
      H(4)=0.                                                          LCL00520
      DO 50006 J=1,4                                                   LCL00530
      PHT(J)=0.                                                        LCL00540
      DO 50006 K=1,4                                                   LCL00550
50006 PHT(J)=PHT(J)+I_LCL$PMATRIX(J,K)*H(K)                            LCL00560
      HPHT=0.                                                          LCL00570
      DO 50007 J=1,4                                                   LCL00580
50007 HPHT=HPHT+H(J)*PHT(J)                                            LCL00590
      HPHTR=HPHT+.25                                                   LCL00600
      DO 50008 J=1,4                                                   LCL00610
50008 K(J)=PHT(J)/HPHTR                                                LCL00620
      Z=FLOAT(LBEAR)                                                   LCL00630
      HX=0.                                                            LCL00640
      DO 50009 J=1,4                                                   LCL00650
50009 HX=HX+H(J)*X(J)                                                  LCL00660
      ZHX=Z-HX                                                         LCL00670
```

```
      DO 50010 J=1,4                                                    LCL00680
50010 PROD(J)=K(J)*ZHX                                                  LCL00690
      DO 50011 J=1,4                                                    LCL00700
50011 XEST(J)=X(J)+PROD(J)                                              LCL00710
      DO 50012 J=1,4                                                    LCL00720
      DO 50012 L=1,4                                                    LCL00730
50012 KPHTT(J,L)=K(J)*PHT(L)                                            LCL00740
      DO 50013 J=1,4                                                    LCL00750
      DO 50013 K=1,4                                                    LCL00760
50013 I_LCL$PMATRIX(J,K)=I_LCL$PMATRIX(J,K)-KPHTT(J,K)                  LCL00770
      THETA=FATAN2(XEST(2),XEST(1))                                     LCL00780
      THETA=INT(THETA*(180./3.141592654)+.5)                            LCL00790
      RNG=SQRT(XEST(1)*XEST(1)+XEST(2)*XEST(2))                         LCL00800
      F_LCL$TMALAT=RORLAT                                               LCL00810
      F_LCL$TMALON=RORLON                                               LCL00820
      COSL=COS(F_LCL$TMALAT)                                            LCL00830
      CALL RRB2LL(F_LCL$TMALAT,F_LCL$TMALON,RNG,THETA,0.,COSL)          LCL00840
      IBB(KPOINT_LCL+8)=IOR(IAND(IBB(KPOINT_LCL+8),NOT(ISHFT(65535,0))),LCL00850
     *ISHFT(IAND(INT(.5+(F_LCL$TMALAT--3.2)/.0001),65535),0))            LCL00860
      IBB(KPOINT_LCL+8)=IOR(IAND(IBB(KPOINT_LCL+8),NOT(ISHFT(65535,16)))LCL00870
     *,ISHFT(IAND(INT(.5+(F_LCL$TMALON--3.2)/.0001),65535),16))          LCL00880
      CSE=FATAN2(XEST(4),XEST(3))                                       LCL00890
      CSE=INT(CSE*(180./3.141592654)+.5)                                LCL00900
      SPD=SQRT(XEST(3)*XEST(3)+XEST(4)*XEST(4))                         LCL00910
```

```
 IBB(KPOINT_LCL+5)=IOR(IAND(IBB(KPOINT_LCL+5),NOT(ISHFT(511,0))),ISLCL00920
*HFT(IAND((CSE),511),0))                                                LCL00930
 IBB(KPOINT_LCL+4)=IOR(IAND(IBB(KPOINT_LCL+4),NOT(ISHFT(4095,16))),LCL00940
*ISHFT(IAND((SPD),4095),16))                                            LCL00950
 CONST1=I_LCL$PMATRIX(1,1)-I_LCL$PMATRIX(2,2)                           LCL00960
 CONST2=I_LCL$PMATRIX(1,2)*I_LCL$PMATRIX(1,2)                           LCL00970
 CONST=SQRT(CONST1*CONST1/4.+CONST2)                                    LCL00980
 I_LCL$SIGMASQR=(I_LCL$PMATRIX(1,1)+I_LCL$PMATRIX(2,2))/2.+CONST        LCL00990
 I_LCL$2SIGMA=SQRT(I_LCL$SIGMASQR)*2./2025.                             LCL01000
 IF(I_LCL$2SIGMA.LE.500)THEN                                            LCL01010
   I_LCL$TMAQUALITY=2                                                   LCL01020
 ELSE IF(I_LCL$2SIGMA.GT.500.AND.I_LCL$2SIGMA.LE.1000)THEN              LCL01030
   I_LCL$TMAQUALITY=1                                                   LCL01040
 ELSE                                                                   LCL01050
   I_LCL$TMAQUALITY=0                                                   LCL01060
 END IF                                                                 LCL01070
 IBB(KPOINT_LCL+9)=IOR(IAND(IBB(KPOINT_LCL+9),NOT(ISHFT(3,4))),ISHFLCL01080
*T(IAND((I_LCL$TMAQUALITY),3),4))                                       LCL01090
 RETURN                                                                 LCL01100
 END                                                                    LCL01110
 SUBROUTINE MUL4X4(A,B,C)                                               LCL01120
 DIMENSION A(4,4),B(4,4),C(4,4)                                         LCL01130
 DO 60000 I=1,4                                                         LCL01140
 DO 60001 J=1,4                                                         LCL01150
```

```
      S=0.                                                    LCL01160
      DO 60002 K=1,4                                          LCL01170
60002 S=S+A(I,K)*B(K,J)                                       LCL01180
60001 C(I,J)=S                                                LCL01190
60000 CONTINUE                                                LCL01200
      RETURN                                                  LCL01210
      END                                                     LCL01220
```

APPENDIX C

MULTIPLE SENSOR MODEL (RATIONAL FORTRAN)

```
Subroutine CORSNR                                                    SNR00010
#####################################################################SNR00020
#                                                                    SNR00030
# Purpose: (1) Correlate all sonar contacts (active and passive) and SNR00040
#              store the updated FIX (Posit,CSE,SPD).                SNR00050
#          (2) Determine a TMA quality based on the criteria:        SNR00060
#              If the semi-major axis of the area of probability is: SNR00070
#                (a) <= 500 yds                                      SNR00080
#                    TMA quality is GOOD                             SNR00090
#                (b) > 500 yds & <= 1000 yds                         SNR00100
#                    TMA quality is FAIR                             SNR00110
#                (c) > 1000 yds                                      SNR00120
#                    TMA quality is POOR                             SNR00130
#                                                                    SNR00140
# Called by: WARCYC                                                  SNR00150
#                                                                    SNR00160
# Calls: CORR_SORT  MUL4X4  RRB2LL                                   SNR00170
#                                                                    SNR00180
#####################################################################SNR00190
```

```
                                                                    SNR00200
BBcommon                                                            SNR00210
CORR$ccmmon                                                         SNR00220
                                                                    SNR00230
real  XEST(4),X(4)                  #System Model State Vector      SNR00240
      PHI(4,4)                      #System Model Transition Matrix SNR00250
      PHIT(4,4)                     #Transpose of Transition Matrix SNR00260
      P(4,4),I_LCL$PMATRIX(4,4)     #Error Covariance Matrix        SNR00270
      H(4)                          #Measurement Model Observation Matrix SNR00280
      KG(4),KGAIN(4,2)              #Kalman Gain                    SNR00290
      Z(2)                          #Measurement Vector             SNR00300
      R(2,2)                        #Measurement Noise              SNR00310
                                                                    SNR00320
                                    #Loop thru Remote Table         SNR00330
for(RMT$Pointer$First; RMT$Pointer$Valid; RMT$Pointer$Next)         SNR00340
   {                                                                SNR00350
   if(xRMT$InUse$I==$no)next        #Finf the right slots           SNR00360
   RMT$DetectionType$i=xRMT$DetectionType$i                         SNR00370
   if(RMT$DetectionType$i=$Sonar$Code)      #If sonar, set composition SNR00380
     putRMT$Compositicn$I(1)                #    to 1               SNR00390
   }                                                                SNR00400
                                                                    SNR00410
if(Correlate$Sonar==$no)return                                       SNR00420
```

```
                                                                    SNR00430
#___________________________________________________________________SNR00440
#Loop for each BLUE/ORANGE View                                     SNR00450
                                                                    SNR00460
for(iview=$firstBLUE$view; iview<=$lastORANGE$view; iview=iview+1)  SNR00470
   {                                                                SNR00480
   VUE$Pointer$To iview           #Get to the right view            SNR00490
                                                                    SNR00500
   RMT$Pointer$To xVUE$FirstRmtIndx$i       #Set first and last     SNR00510
   istart=RMT$Pointer                       #    RMT Index as       SNR00520
   RMT$Pointer$To xVUE$LastRmtIndx$i        #    limits for loop    SNR00530
   iend=RMT$Pointer                                                 SNR00540
                                                                    SNR00550
   kore=0                         #Initialize counter               SNR00560
                                  #Loop for each RMT slot in View   SNR00570
   for(RMT$Pointer=istart; RMT$Pointer<=iend; RMT$Pointer$next)     SNR00580
      {                                                             SNR00590
      if(XRMT$InUse$i==$no)next   #Skip if not in use               SNR00600
      RMT$DetectionType$i=xRMT$DetectionType$i   #Get Detection Type SNR00610
                                                                    SNR00620
      if(Correlate$Sonar==$yes & RMT$DetectionType$i==$Sonar$Code)  SNR00630
      *continue                                                     SNR00640
      else next                                                     SNR00650
                                                                    SNR00660
```

```
   if(kore>=$Max$Corr)break          #Make sure that there are enough SNR00670
                                     #    slots for the array          SNR00680
   kore=kore+1                       #Add to array counter             SNR00690
   irmtp(kore)=RMT$Pointer           #Save RMT Pointer                 SNR00700
   idtor(kore)=xRMT$Detector$I       #Save Detector                    SNR00710
   idtee(kore)=xRMT$Detectee$I       #Save Detectee                    SNR00720
   ilast(kore)=xRMT$LastDetTime$I    #Save time of detection update    SNR00730
   ibear(kore)=xRMT$Bearing$I        #Save the bearing                 SNR00740
   irnge(kore)=xRMT$Range$I          #Save the range                   SNR00750
   ipnt(kore)=kore                   #Initialize sort index            SNR00760
   }                                                                   SNR00770
                                                                       SNR00780
if(kore==0)return                 #Quit if no tracks                  SNR00790
                                                                       SNR00800
CALL CORR_SORT                    #Sort arrays by Detectee/Last-Det-TimeSNR00810
                                                                       SNR00820
for(k=1; k<kore; k=j)                                                  SNR00830
   {                                                                   SNR00840
   k1=ipnt(k)                                                          SNR00850
                                                                       SNR00860
   KPCINT_RMT=irmtp(k1)           #Set pointer                        SNR00870
                                                                       SNR00880
   RMT$TMALAT$F=xRMT$TMALAT$F        #Get posit,CSE,SPD               SNR00890
   RMT$TMALON$F=xRMT$TMALON$F        #    of last TMA estimate        SNR00900
```

```
      RMT$TMACSE$F=xRMT$TMACSE$F                                        SNR00910
      RMT$TMASPD$F=xRMT$TMASPD$F                                        SNR00920
                                                                        SNR00930
      POS1$LAT$F=xPOS1$LAT$F      #Get posit of Detector                SNR00940
      POS1$LON$F=xPOS1$LON$F                                            SNR00950
      POS1$COSLAT$F=xPOS1$COSLAT$F                                      SNR00960
                                                                        SNR00970
#MOVEMENT:                                                              SNR00980
                              #State Extrapolation                      SNR00990
      XEST(1)=X                    #Distance in north-south direction   SNR01000
      ANGPI(DELLON)                #Insure shortway around earth        SNR01010
      XEST(2)=Y                    #Distance in east-west direction     SNR01020
      XEST(3)=X$dot                #Speed vector in north-south direction SNR01030
      XEST(4)=Y$dot                #Speed vector in east-west direction SNR01040
                                                                        SNR01050
      #Initialize the PHI matrix                                        SNR01060
         PHI(1,3)=PHI(2,4)=$delta$t     #Movement time in hrs since     SNR01070
                                        #    last update                SNR01080
                                                                        SNR01090
      #X$hat=PHI*X$hat             State Extrapolation Vector          SNR01100
                                                                        SNR01110
      #PHI$transpose                                                    SNR01120
      #P=PHI*P*PHI$transpose       Error Covariance Extrapolation      SNR01130
```

```
                                                                    SNR01140
#MEASUREMENT:                                                       SNR01150
                                                                    SNR01160
      for(j=k; j<=kore; j=j+1)                                      SNR01170
         {                                                          SNR01180
         j1=ipnt(j)                                                 SNR01190
                                                                    SNR01200
         if(idtee(k1) != idtee(j1))break                            SNR01210
                                                                    SNR01220
         KPOINT_RMT=irmtp(j1)      #Set pointer                     SNR01230
                                                                    SNR01240
         RMT$DetecticnType=xRMT$DetectionType    #Get Detection Type SNR01250
                                                                    SNR01260
         #Estimated bearing                                         SNR01270
         #Estimated range                                           SNR01280
                                                                    SNR01290
         if(k=j)                   #ORIGIN platform                 SNR01300
           POS2$LAT$F=xPOS2$LAT$F   #Get posit of next detector     SNR01310
           POS2$LON$F=xPOS2$LON$F                                   SNR01320
           POS2$COSLAT$F=xPOS2$COSLAT$F                             SNR01330
                                                                    SNR01340
         #Adjust contact bearing to ORIGIN                         SNR01350
         #X=north-south distance from ORIGIN to DETECTOR           SNR01360
         #Y=east-west distance from ORIGIN to DETECTOR             SNR01370
```

```
#THETAK=bearing from ORIGIN to DETECTOR                              SNR01380
#DK=distance from ORIGIN to DETECTOR                                 SNR01390
                                                                     SNR01400
ibear(j1)=DK*SIN(OBS BRG - BRG from ORIGIN)   #Observed bearing      SNR01410
                                              #adjusted to           SNR01420
                                              #ORIGIN platform       SNR01430
                                                                     SNR01440
if(RMT$DetectionType != $Passive$Sonar) check for $Active$Sonar      SNR01450
                                                                     SNR01460
                          #Measurement Observation Matrix            SNR01470
  H(1)=-SIN(THETA$hat)/RNG$hat      #H=H$transpose                   SNR01480
  H(2)=COS(THETA$hat)/RNG$hat                                        SNR01490
  H(3)=H(4)=0                                                        SNR01500
                                                                     SNR01510
  #P*H$transpose          =(P*H$transpose)$transpose                 SNR01520
  #H*P*H$transpose                                                  SNR01530
  #H*P*H$transpose+R      R=BRG measurement error=±.5 degrees        SNR01540
  #Kalman Gain                                                       SNR01550
                                                                     SNR01560
  #Z(1)=measured bearing                                            SNR01570
  #H*X$hat                                                          SNR01580
  #ZHX=Z(bearing)-H*X$hat      Measurement Residual                  SNR01590
  #K*(Z-H*X$hat)                                                    SNR01600
  #X$hat=X$hat+K*(Z-H*X$hat)  State Update                          SNR01610
```

```
                                                                    SNR01620
  #K*(P*H$transpose)$transpose                                      SNR01630
  #P=P-K*(P*H$transpose)$transpose      Error Covariance UpdateSNR01640
                                                                    SNR01650
if(RMT$DetectionType != $Active$Sonar)break                         SNR01660
                                                                    SNR01670
  #irnge(j1)=observed range adjusted to ORIGIN platform             SNR01680
                                                                    SNR01690
                              #Measurement Observation Matrix       SNR01700
  HH(2,1)=COS(THETA$hat)                                            SNR01710
  HH(2,2)=SIN(THETA$hat)                                            SNR01720
  HH(1,1)=-SIN(THETA$hat)/RNG$hat                                   SNR01730
  HH(1,2)=COS(THETA$hat)/RNG$hat                                    SNR01740
  HH(1,3)=HH(1,4)=HH(2,3)=HH(2,4)=0                                 SNR01750
                                                                    SNR01760
  #H$transpose                                                      SNR01770
  #P*H$transpose                                                    SNR01780
  #H*P*H$transpose                                                  SNR01790
  #H*P*H$transpose+R     R=BRG measurement error=±.5 degrees  SNR01800
                        # =RNG measurement error=±.5 naut. mi.SNR01810
  #(H*P*H$transpose+R)$inverse                                      SNR01820
  #Kalman Gain                                                      SNR01830
                                                                    SNR01840
  #Z(1)=measured bearing                                            SNR01850
```

```
      #Z(2)=measured range                                                    SNR01860
      #H*X$hat                                                                SNR01870
      #Z-H*X$hat              Measurement Residual                            SNR01880
      #K*(Z-H*X$hat)                                                          SNR01890
      #X$hat=X$hat+K*(Z-H*X$hat)   State Update                               SNR01900
                                                                              SNR01910
      #(P*H$transpose)$transpose                                              SNR01920
      #K*(P*H$transpose)$transpose                                            SNR01930
      #P=P-K*(P*H$transpose)$transpose      Error Covariance UpdateSNR01940
   }                                                                          SNR01950
                                                                              SNR01960
#New estimated bearing                                                        SNR01970
#New estimated range                                                          SNR01980
                                                                              SNR01990
#Compute LAT/LON of BRG/RNG from ORIGIN                                       SNR02000
   CALL RRB2LL(_              #Get LAT/LON                                    SNR02010
        F_RMT$TMALAT          #ORIGIN LAT->FIX LAT (input/output)             SNR02020
        F_RMT$TMALON          #ORIGIN LON->FIX LON (input/output)             SNR02030
        RNG                   #Range from ORIGIN to TARGET                    SNR02040
        THETA                 #Bearing from ORIGIN to TARGET                  SNR02050
        0.0                   #Pass zero                                      SNR02060
        COSL                  #Cosine of latitude (input/output)              SNR02070
                                                                              SNR02080
putRMT$TMALAT$f               #New FIX position                               SNR02090
```

```
    putRMT$TMALON$f                                                    SNR02100
                                                                       SNR02110
    #New estimated course                                              SNR02120
    #New estimated speed                                               SNR02130
                                                                       SNR02140
    putRMT$TMACSE$f             #New FIX course                        SNR02150
    putRMT$TMASPD$f             #    and speed                         SNR02160
                                                                       SNR02170
    #Determine semi-major axis of area of probability                  SNR02180
      #SIGMA$squared=(P11+P22)/2+SQRT{((P11-P22)+(P11-P22))/4+P12*P12}  SNR02190
      #2SIGMA=2*SIGMA/2025 yds                                          SNR02200
                                                                       SNR02210
    if(2SIGMA <= 500 yds)then                                          SNR02220
      TMA$Quality=2             #GOOD                                  SNR02230
    else if(2SIGMA > 500 yds & <= 1000 yds)then                        SNR02240
      TMA$Quality=1             #FAIR                                  SNR02250
    else(2SIGMA > 1000 yds)                                            SNR02260
      TMA$Quality=0             #POOR                                  SNR02270
                                                                       SNR02280
    }k=j                        #Set pointer to next detectee          SNR02290
                                                                       SNR02300
}                                                                      SNR02310
```

```
                                                                    SNR02320
      return                                                        SNR02330
      end               #End CORSNR                                 SNR02340
```

APPENDIX D

MULTIPLE SENSOR MODEL (SOURCE CODE)

```
      SUBROUTINE CORSNR                                                    COR00010
      IMPLICIT REAL*8 (A,C)                                                COR00020
      INTEGER IBB(1025)                                                    COR00030
      INTEGER*2 IBBW(2,1025),IDTOR(800),IDTEE(800),ILAST(800),IBEAR(800)   COR00040
      INTEGER*2 IRNGE(800),IPNT(800),KORE                                  COR00050
      INTEGER*4 IRMTP(800)                                                 COR00060
      BYTE IBBB(4,1025)                                                    COR00070
      REAL*8 CBB(512)                                                      COR00080
      REAL FBB(1025),PBB(4,1025),H(4),PHT(4),KG(4),HPHT,HPHTR,HX,PROD(4)   COR00090
      REAL KGAIN(4,2),I_RMT$PMATRIX(4,4),KPHTT(4,4),KKPHTT(4,4),R(2,2)     COR00100
      REAL HH(2,4),HHT(4,2),PPHT(4,2),HHPHT(2,2),SUM(2,2),ADJ(2,2)         COR00110
      REAL INVSUM(2,2),PHI(4,4),PHIT(4,4),P(4,4),HHX(2),PPHTT(2,4),X(4)    COR00120
      REAL XEST(4),Z(2),KZHX(4)                                            COR00130
      EQUIVALENCE (IBB,FBB,CBB,IBBW,IBBB,PBB)                              COR00140
      EQUIVALENCE (IBB(513),IBBP)                                          COR00150
      COMMON/BBOARD/IEB                                                    COR00160
      COMMON/SCRPAD/IRMTP,IDTOR,IDTEE,ILAST,IBEAR,IRNGE,IPNT,KORE          COR00170
      DATA R/.25,0.,0.,.25/                                                COR00180
      KPOINT_RMT=IBBP(1,56)                                                COR00190
70000 IF(.NOT.((KPOINT_RMT.GE.IEBP(1,56).AND.KPOINT_RMT.LT.(IBBP(1,56)+ICOR00200
     *BBP(2,56))))GOTO 70001                                               COR00210
```

```
      IF(IBB(KPOINT_RMT+8).EQ.0)GOTO 70002                              COR00220
      IBB(KPOINT_RMT+10)=IOR(IAND(IBB(KPOINT_RMT+10),NOT(ISHFT(1,29))),ICOR00230
     *SHFT(IAND((0),1),29))                                             COR00240
      IBB(KPOINT_RMT+10)=IOR(IAND(IBB(KPOINT_RMT+10),NOT(ISHFT(1,28))),ICOR00250
     *SHFT(IAND(('00000001'X),1),28))                                   COR00260
      IBB(111)=1                                                        COR00270
      I_RMT$DETECTIONTYPE=(IAND(ISHFT(IBB(KPOINT_RMT+8),-29),3))        COR00280
      IF(.NOT.(I_RMT$DETECTIONTYPE.EQ.2.OR.I_RMT$DETECTIONTYPE.EQ.24))GOCOR00290
     *TO 70002                                                          COR00300
      IBB(KPOINT_RMT+10)=IOR(IAND(IBB(KPOINT_RMT+10),NOT(ISHFT(3,23))),ICOR00310
     *SHFT(IAND((1),3),23))                                             COR00320
      IBB(KPOINT_RMT+10)=IOR(IAND(IBB(KPOINT_RMT+10),NOT(ISHFT(1,28))),ICOR00330
     *SHFT(IAND(('00000001'X),1),28))                                   COR00340
      IBB(111)=1                                                        COR00350
70002 KPOINT_RMT=KPOINT_RMT+15                                          COR00360
      GOTO 70000                                                        COR00370
70001 IF(IBB(256).EQ.0)GOTO 70099                                       COR00380
      IVIEW=IBB(129)                                                    COR00390
70003 IF(.NOT.(IVIEW.LE.IBB(132)))GOTO 70099                            COR00400
      KPOINT_VUE=IBBP(1,06)-1540+1540*IVIEW                             COR00410
      KPOINT_RMT=IBBP(1,56)-15+15*(IAND(ISHFT(IBB(KPOINT_VUE+1),-0),1638COR00420
     *3))                                                               COR00430
      ISTART=KPOINT_RMT                                                 COR00440
      KPOINT_RMT=IBBP(1,56)-15+15*(IAND(ISHFT(IBB(KPOINT_VUE+1),-14),163COR00450
```

```
     *83))                                                                  COR00460
      IEND=KPOINT_RMT                                                       COR00470
      KORE=0                                                                COR00480
      KPOINT_RMT=ISTART                                                     COR00490
70004 IF(.NOT.(KPOINT_RMT.LE.IEND))GOTO 70005                              COR00500
      IF(IBB(KPOINT_RMT+8).EQ.0)GOTO 70006                                  COR00510
      I_RMT$DETECTIONTYPE=(IAND(ISHFT(IBB(KPOINT_RMT+8),-29),3))            COR00520
      IF(IBB(256).EQ.1.AND.(I_RMT$DETECTIONTYPE.EQ.2.OR.I_RMT$DETECTIONTCOR00530
     *YPE.EQ.24))GOTO 70007                                                 COR00540
      GOTO 70006                                                            COR00550
70007 IF(KORE.GE.800)GOTO 70005                                             COR00560
      KORE=KORE+1                                                           COR00570
      IRMTP(KORE)=KPOINT_RMT                                                COR00580
      IDTOR(KORE)=(IAND(ISHFT(IBB(KPOINT_RMT+8),-10),1023))                 COR00590
      IDTEE(KORE)=(IAND(ISHFT(IBB(KPOINT_RMT+7),-0),1023))                  COR00600
      ILAST(KORE)=(IAND(ISHFT(IBB(KPOINT_RMT+2),-0),65535))                 COR00610
      IBEAR(KORE)=(IAND(ISHFT(IBB(KPOINT_RMT+7),-10),511))                  COR00620
      IRNGE(KORE)=(IAND(ISHFT(IBB(KPOINT-RMT+7),-0),511))                   COR00630
      IPNT(KORE)=KORE                                                       COR00640
70006 KPOINT_RMT=KPOINT_RMT+15                                              COR00650
      GOTO 70004                                                            COR00660
70005 IF(KORE.EQ.0)GOTO 70099                                               COR00670
      CALL CORR_SORT                                                        COR00680
      K=1                                                                   COR00690
```

```
      J=K                                                                COR00700
70009 IF(.NOT.(K.LT.KORE))GOTO 70010                                     COR00710
      K1=IPNT(K)                                                         COR00720
      KPOINT_RMT=IRMTP(K1)                                               COR00730
      F_RMT$TMALAT=(IAND(ISHFT(IBB(KPOINT_RMT+8),-0),65535)*1.*.0001-3.2COR00740
     *)                                                                  COR00750
      F_RMT$TMALON=(IAND(ISHFT(IBB(KPOINT_RMT+8),-16),65535)*1.*.0001-3.COR00760
     *2)                                                                 COR00770
      F_RMT$TMACSE=(IAND(ISHFT(IBB(KPOINT_RMT+5),-0),511))               COR00780
      F_RMT$TMASPD=(IAND(ISHFT(IBB(KPOINT_RMT+4),-16),4095))             COR00790
      F_POS1$LAT=FBB(KPOIONT_RMT)                                        COR00800
      F_POS1$LON=FBB(KPOINT_RMT+1)                                       COR00810
      F_POS1$COSLAT=FBB(KPOINT_RMT+13)                                   COR00820
      XEST(1)=F_RMT$TMALAT-F_POS1$LAT                                    COR00830
      DELLON=F_RMT$TMALON-F_POS1$LON                                     COR00840
      ANGPI(DELLON)                                                      COR00850
      COSL=COS(F_RMT$TMALAT)                                             COR00860
      XEST(2)=.5*(COSL+F_POS1$CCSLAT)*DELLON                             COR00870
      XEST(3)=F_RMT$TMASPD*COS(F_RMT$TMACSE)                             COR00880
      XEST(4)=F_RMT$TMASPD*SIN(F_RMT$TMACSE)                             COR00890
      DO 70011 JJ=1,4                                                    COR00900
      DO 70011 KK=1,4                                                    COR00910
      IF(.NOT.(JJ.EQ.KK))GOTO 70012                                      COR00920
      PHI(JJ,KK)=1.                                                      COR00930
```

```
      GOTO 70011                                                        COR00940
70012 PHI(JJ,KK)=0.                                                     COR00950
70011 CONTINUE                                                          COR00960
      F_RMT$DELTIME=(IBB(103)-IIAST(K1))/60.                            COR00970
      PHI(1,3)=F_RMT$LELTIME                                            COR00980
      PHI(2,4)=F_RMT$DELTIME                                            COR00990
      DO 70013 JJ=1,4                                                   COR01000
      X(JJ)=0.                                                          COR01010
      DO 70013 KK=1,4                                                   COR01020
70013 X(J)=X(J)+PHI(JJ,KK)*XEST(KK)                                     COR01030
      DO 70014 JJ=1,4                                                   COR01040
      DO 70014 KK=1,4                                                   COR01050
70014 PHIT(JJ,KK)=PHT(KK,JJ)                                            COR01060
      CALL MUL4X4(PHI,I_RMT$PMATRIX,P)                                  COR01070
      CALL MUL4X4(P,PHIT,I_RMT$PMATRIX)                                 COR01080
70015 IF(.NOT.(J.LE.KORE))GOTO 70016                                    COR01090
      J1=IPNT(J)                                                        COR01100
      IF(IDTEE(K1).NE.IDTEE(J1))GOTO 70017                              COR01110
      KPOINT_RMT=IRMTP(J1)                                              COR01120
      I_RMT$DETECTIONTYPE=(IAND(ISHFT(IBB(KPOINT_RMT+8),-29),3))        COR01130
      THETA=FATAN2(X(2),X(1))                                           COR01140
      THETA=INT(THETA*(180./3.141592654)+.5)                            COR01150
      RNG=SQRT(X(1)*X(1)+X(2)*X(2))                                     COR01160
      IF(K.EQ.J)GOTO 70008                                              COR01170
```

```
      F_POS2$LAT=FBB(KPOINT_RMT)                                        COR01180
      F_POS2$LON=FBB(KPOINT_RMT+1)                                      COR01190
      F_POS2$COSLAT=FBB(KPOINT_RMT+13)                                  COR01200
      X=F_POS2$LAT-F_POS1$LAT                                           COR01210
      Y=F_POS2$LON-F_POS1$LON                                           COR01220
      ANGPI(Y)                                                          COR01230
      COSL=COS(F_POS2$LAT)                                              COR01240
      Y=.5*(F_POS2$COSLAT+F_POS1$COSLAT)*Y                              COR01250
      THETAK=FATAN2(Y,X)                                                COR01260
      THETAK=INT(THETAK*(180./3.141592654)+.5)                          COR01270
      DK=SQRT(X*X+Y*Y)                                                  COR01280
      IBEAR(J1)=DK*SIN(IBEAR(J1)-THETAK)                                COR01290
70008 IF(.NOT.(I_RMT$DETECTIONTYPE.EQ.2))GOTO 70018                     COR01300
      H(1)=-SIN(THETA)/RNG                                              COR01310
      H(2)=COS(THETA)/RNG                                               COR01320
      H(3)=0.                                                           COR01330
      H(4)=0.                                                           COR01340
      DO 70019 JJ=1,4                                                   COR01350
      PHT(JJ)=0.                                                        COR01360
      DO 70019 KK=1,4                                                   COR01370
70019 PHT(JJ)=PHT(JJ)+I_RMT$PMATRIX(JJ,KK)*H(KK)                        COR01380
      HPHT=0.                                                           COR01390
```

```
      DO 70020 JJ=1,4                                                    COR01400
70020 HPHT=HPHT+H(JJ)*PHT(JJ)                                            COR01410
      HPHTR=HPHT+.25                                                     COR01420
      DO 70021 JJ=1,4                                                    COR01430
70021 KG(JJ)=PHT(JJ)/HPHTR                                               COR01440
      Z(1)=FLOAT(IBEAR(J1))                                              COR01450
      HX=0.                                                              COR01460
      DO 70022 JJ=1,4                                                    COR01470
70022 HX=HX+H(JJ)*X(JJ)                                                  COR01480
      ZHX=Z(1)-HX                                                        COR01490
      DO 70023 JJ=1,4                                                    COR01500
70023 PROD(JJ)=KG(JJ)*ZHX                                                COR01510
      DO 70024 JJ=1,4                                                    COR01520
70024 X(JJ)=X(JJ)+PROD(JJ)                                               COR01530
      DO 70025 JJ=1,4                                                    COR01540
      DO 70025 KK=1,4                                                    COR01550
70025 KPHTT(JJ,KK)=KG(JJ)*PHT(KK)                                        COR01560
      DO 70026 JJ=1,4                                                    COR01570
      DO 70026 KK=1,4                                                    COR01580
70026 I_RMT$PMATRIX(JJ,KK)=I_RMT$PMATRIX(JJ,KK)-KPHTT(JJ,KK)             COR01590
      GOTO 70027                                                         COR01600
70018 IF(.NOT.(I_RMT$DETECTIONTYPE.EQ.24))GOTO 70027                     COR01610
      IF(K.EQ.J)GOTO 70028                                               COR01620
```

```
      IRNGE(J1)=SQRT(DK*DK+IRNGE(J1)*IRNGE(J1))                    COR01630
70028 HH(2,1)=COS(THETA)                                           COR01640
      HH(2,2)=SIN(THETA)                                           COR01650
      HH(1,1)=-H(2,2)/RNG                                          COR01660
      HH(1,2)=H(2,1)/RNG                                           COR01670
      HH(1,3)=0.                                                   COR01680
      HH(1,4)=0.                                                   COR01690
      HH(2,3)=0.                                                   COR01700
      HH(2,4)=0.                                                   COR01710
      DO 70029 JJ=1,4                                              COR01720
      DO 70029 KK=1,4                                              COR01730
70029 HHT(JJ,KK)=HH(KK,JJ)                                         COR01740
      DO 70030 JJ=1,4                                              COR01750
      DO 70031 KK=1,2                                              COR01760
      S=0.                                                         COR01770
      DO 70032 LL=1,4                                              COR01780
70032 S=S+I_RMT$PMATRIX(JJ,LL)*HHT(LL,KK)                          COR01790
70031 PPHT(JJ,KK)=S                                                COR01800
70030 CONTINUE                                                     COR01810
      DO 70033 JJ=1,2                                              COR01820
      DO 70034 KK=1,2                                              COR01830
      S=0.                                                         COR01840
```

```
      DO 70035 LL=1,4                                                    COR01850
70035 S=S+HH(JJ,LL)*PPHT(LL,KK)                                          COR01860
70034 HHPHT(JJ,KK)=S                                                     COR01870
70033 CONTINUE                                                           COR01880
      DO 70036 JJ=1,2                                                    COR01890
      DO 70036 KK=1,2                                                    COR01900
70036 SUM(JJ,KK)=HHPHT(JJ,KK)+R(JJ,KK)                                   COR01910
      DET=SUM(1,1)*SUM(2,2)-SUM(1,2)*SUM(2,1)                            COR01920
      ADJ(1,1)=SUM(2,2)                                                  COR01930
      ADJ(1,2)=-SUM(1,2)                                                 COR01940
      ADJ(2,1)=-SUM(2,1)                                                 COR01950
      ADJ(2,2)=SUM(1,1)                                                  COR01960
      DO 70037 JJ=1,2                                                    COR01970
      DO 70037 KK=1,2                                                    COR01980
70037 INVSUM(JJ,KK)=ADJ(JJ,KK)/DET                                       COR01990
      DO 70038 JJ=1,4                                                    COR02000
      DO 70039 KK=1,2                                                    COR02010
      S=0.                                                               COR02020
      DO 70040 LL=1,2                                                    COR02030
70040 S=S+PPHT(JJ,LL)*INVSUM(LL,KK)                                      COR02040
70039 KGAIN(JJ,KK)=S                                                     COR02050
70038 CONTINUE                                                           COR02060
      Z(1)=FLOAT(IBEAR(J1))                                              COR02070
      Z(2)=FLOAT(IRNGE(J1))                                              COR02080
```

```
      DO 70041 JJ=1,2                                                  COR02090
      S=0.                                                             COR02100
      DO 70042 KK=1,4                                                  COR02110
70042 S=S+HH(JJ,KK)*X(KK)                                              COR02120
70041 HHX(JJ)=S                                                        COR02130
      DO 70043 JJ=1,2                                                  COR02140
70043 HHX(JJ)=Z(JJ)-HHX(JJ)                                            COR02150
      DO 70044 JJ=1,4                                                  COR02160
      S=0.                                                             COR02170
      DO 70045 KK=1,2                                                  COR02180
70045 S=S+KGAIN(JJ,KK)*HHX(KK)                                         COR02190
70044 KZHX(JJ)=S                                                       COR02200
      DO 70046 JJ=1,4                                                  COR02210
70046 X(JJ)=X(JJ)+KZHX(JJ)                                             COR02220
      DO 70047 JJ=1,2                                                  COR02230
      DO 70047 KK=1,4                                                  COR02240
70047 PPHTT(JJ,KK)=PPHT(KK,JJ)                                         COR02250
      DO 70048 JJ=1,4                                                  COR02260
      DO 70049 KK=1,4                                                  COR02270
      S=0.                                                             COR02280
      DO 70050 LL=1,2                                                  COR02290
70050 S=S+KGAIN(JJ,LL)*PPHTT(LL,KK)                                    COR02300
70049 KKPHTT(JJ,KK)=S                                                  COR02310
70048 CONTINUE                                                         COR02320
```

```
      DO 70051 JJ=1,4                                                    COR02330
      DO 70051 KK=1,4                                                    COR02340
70051 I_RMT$PMATRIX(JJ,KK)=I_RMT$PMATRIX(JJ,KK)-KKPHTT(JJ,KK)            COR02350
70027 J=J+1                                                              COR02360
      GOTO 70015                                                         COR02370
70017 THETA=FATAN2(X(2),X(1))                                            COR02380
      THETA=INT(THETA*(180./3.141592654)+.5)                             COR02390
      RNG=SQRT(X(1)*X(1)+X(2)*X(2))                                      COR02400
      F_RMT$TMALAT=F_POS1$LAT                                            COR02410
      F_RMT$TMALON=F_POS1$LON                                            COR02420
      COSL=F_POS1$COSLAT                                                 COR02430
      CALL RRB2LL(F_RMT$TMALAT,F_RMT$TMALON,RNG,THETA,0.,COSL)           COR02440
      KPOINT_RMT=IRMTI(1)                                                COR02450
      IBB(KPOINT_RMT+8)=IOR(IAND(IBB(KPOINT_RMT+8),NOT(ISHFT(65535,0))),COR02460
     *ISHFT(IAND(INT(.5+(F_RMT$TMALAT--3.2)/.0001),65535),0))            COR02470
      IBB(KPOINT_RMT+8)=IOR(IAND(IBB(KPOINT_RMT+8),NOT(ISHFT(65535,16)))COR02480
     *,ISHFT(IAND(INT(.5+(F_RMT$TMALON--3.2)/.0001),65535),16))          COR02490
      CSE=FATAN2(X(4),X(3))                                              COR02500
      CSE=INT(CSE*(180./3.141592654)+.5)                                 COR02510
      SPD=SQRT(X(3)*X(3)+X(4)*X(4))                                      COR02520
      IBB(KPOINT_RMT+5)=IOR(IAND(IBB(KPOINT_RMT+5),NOT(ISHFT(511,0))),ISCOR02530
     *HFT(IAND((CSE),511),0))                                           COR02540
      IBB(KPOINT_RMT+4)=IOR(IAND(IBB(KPOINT_RMT+4),NOT(ISHFT(4095,16))),COR02550
     *ISHFT(IAND((SPD),4095),16))                                       COR02560
```

```
      CONST1=I_RMT$PMATRIX(1,1)-I_RMT$PMATRIX(2,2)                          COR02570
      CONST2=I_RMT$PMATRIX(1,2)*I_RMT$PMATRIX(1,2)                          COR02580
      CONST=SQRT(CONST1*CONST1/4.+CONST2)                                   COR02590
      I_RMT$SIGMASQR=(I_RMT$PMATRIX(1,1)+I_RMT$PMATRIX(2,2))/2.+CONST       COR02600
      I_RMT$2SIGMA=SQRT(I_RMT$SIGMASQR)*2./2025.                            COR02610
      IF(I_RMT$2SIGMA.LE.500)THEN                                           COR02620
         I_RMT$TMAQUALITY=2                                                 COR02630
      ELSE IF(I_RMT$2SIGMA.GT.500.AND.I_RMT$2SIGMA.LE.1000)THEN             COR02640
         I_RMT$TMAQUALITY=1                                                 COR02650
      ELSE                                                                  COR02660
         I_RMT$TMAQUALITY=0                                                 COR02670
      END IF                                                                COR02680
      IBB(KPOINT_RMT+9)=IOR(IAND(IBB(KPOINT_RMT+9),NOT(ISHFT(3,4))),ISHFCOR02690
     *T(IAND((I_RMT$TMAQUALITY),3),4))                                      COR02700
70016 K=J                                                                   COR02710
      GOTO 70009                                                            COR02720
70010 IVIEW=IVIEW+1                                                         COR02730
      GOTO 70003                                                            COR02740
70099 RETURN                                                                COR02750
      END                                                                   COR02760
```

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